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L41 same (edge\$4 near2 position)	1

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<i>DB=USPT; PLUR=YES; OP=ADJ</i>			
<u>L1</u>	edge\$5 near5 chain	5318	<u>L1</u>
<u>L2</u>	L1 same poistion\$3	0	<u>L2</u>
<u>L3</u>	L1 same position\$3	1753	<u>L3</u>
<u>L4</u>	L3 same (direction or orientation)	500	<u>L4</u>
<u>L5</u>	L4 same ((neighbor\$5 or adjacen\$3) near5 (position\$3 or distance))	34	<u>L5</u>
<u>L6</u>	L5 same (edge near3 (position or direction))	8	<u>L6</u>
<u>L7</u>	((succession or series or chain) near2 edge\$5)	6272	<u>L7</u>
<u>L8</u>	L7 same ((neighbor\$5 or adjacen\$3) near3 edge\$5)	535	<u>L8</u>
<u>L9</u>	L8 same (edge\$5 near2 (position\$3 or direction\$2 or orientation))	40	<u>L9</u>
<u>L10</u>	L9 same ((neighbor\$5 or adjacen\$3) near3 position\$3)	11	<u>L10</u>
<u>L11</u>	L9 same imag\$3	3	<u>L11</u>
<i>DB=USPT,EPAB,JPAB,DWPI; PLUR=YES; OP=ADJ</i>			
<u>L12</u>	((link\$3 or chain) near2 edge\$4) with position\$3	1263	<u>L12</u>

<u>L13</u>	L12 same ((neighbor\$5 or adjacen\$4) near2 edge\$4)	102	<u>L13</u>
<u>L14</u>	L13 same (edge\$4 near3 (direction\$2 or orientation or angle))	0	<u>L14</u>
<u>L15</u>	L13 same (direction\$2 or orientation)	24	<u>L15</u>
<u>L16</u>	L15 same imag\$3	1	<u>L16</u>
<u>L17</u>	edge\$4 near3 position\$3 near3 direction\$2	0	<u>L17</u>
<u>L18</u>	edge\$4 near3 position\$3 near3 direction\$2	3502	<u>L18</u>
<u>L19</u>	L18 same (neighbor\$5 or adjacen\$4)	374	<u>L19</u>
<u>L20</u>	L19 same ((neighbor\$5 or adjacen\$3) near3 position\$3)	129	<u>L20</u>
<u>L21</u>	L20 same edgelet	0	<u>L21</u>
<u>L22</u>	L20 same imag\$3	8	<u>L22</u>
<u>L23</u>	L20 and ((link\$3 or chain) near2 edge\$4)	5	<u>L23</u>
<u>L24</u>	triangular\$6 and marian	22	<u>L24</u>
<u>L25</u>	L24 and (adjacen\$3 or neighbor\$6)	16	<u>L25</u>
<u>L26</u>	edgelet	8	<u>L26</u>
<u>L27</u>	((connect\$3 near1 edge\$4) or (chain near1 edge\$4) or (link\$3 near1 edge\$4)) same (direction\$3 or orientation or angle)	7995	<u>L27</u>
<u>L28</u>	L27 same (edge\$4 near3 position\$3)	373	<u>L28</u>
<u>L29</u>	L28 same (neighbor\$5 or adjacen\$4)	93	<u>L29</u>
<u>L30</u>	L29 same (match\$3 or compar\$6)	4	<u>L30</u>
<u>L31</u>	L29 same imag\$3	4	<u>L31</u>
<u>L32</u>	((connect\$3 near1 edge\$4) or (chain near1 edge\$4) or (link\$3 near1 edge\$4)) same (edge\$4 near4 (direction\$3 or orientation or angle))	2086	<u>L32</u>
<u>L33</u>	L32 same (edge\$4 near3 (direction or orientation or angle))	1535	<u>L33</u>
<u>L34</u>	L33 same ((neighbor\$5 or adjacen\$3) near10 edge\$4)	193	<u>L34</u>
<u>L35</u>	L34 same imag\$3	13	<u>L35</u>
<u>L36</u>	L34 same (defect\$4 or degrad\$3 or pattern)\$5	0	<u>L36</u>
<u>L37</u>	L34 same (defect\$4 or degrad\$3 or pattern)	6	<u>L37</u>
<u>L38</u>	L34 same examin\$6	2	<u>L38</u>
<u>L39</u>	L34 same (edge\$4 near2 direction\$3)	57	<u>L39</u>
<u>L40</u>	L39 same (edge\$4 near2 position\$3)	7	<u>L40</u>
<u>L41</u>	L34 same ((neighbor\$5 or adjacen\$3) near2 edge\$4)	102	<u>L41</u>
<u>L42</u>	L41 same (edge\$4 near2 position)	1	<u>L42</u>

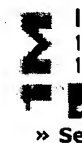
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1 Generalized impedance control of robot for assembly tasks requiring compliant manipulation

Chan, S.P.; Liaw, H.C.;

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Pages:453 - 461
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Ergen, M.; Coleri, S.; Dundar, B.; Jain, R.; Puri, A.; Varaiya, P.;

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3 Implementation of generalized impedance control for robot manipulators

Chan, S.P.;

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Pages:418 - 423 vol.1
[\[Abstract\]](#) [\[PDF Full-Text \(412 KB\)\]](#) IEEE CNF
4 Character grouping technique using 3D neighborhood graphs in rast map

Yong-Bin Kang; Se-Young Ok; Hwan-Gue Cho;

Pattern Recognition, 1998. Proceedings. Fourteenth International Conference on , Volume: 2 , 16-20 Aug. 1998

Pages:1092 - 1094 vol.2

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5 Object recognition: obtaining 2-D reconstructions from color edges

Bellaire, G.; Talmi, K.; Oezguer, E.; Koschan, A.;

Image Analysis and Interpretation, 1998 IEEE Southwest Symposium on , 5-7 1998

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Chan, S.P.; Liaw, H.C.;

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2 Deriving traffic demands for operational IP networks: methodology and experience*Feldmann, A.; Greenberg, A.; Lund, C.; Reingold, N.; Rexford, J.; True, F.;*Networking, IEEE/ACM Transactions on , Volume: 9 , Issue: 3 , June 2001
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